Amendment to the Claims:

This listing of claims will replace all prior versions, and listing of claims in the application.

Listing of Claims:

1.   (Currently Amended) A method of composing an image [IM], the method comprising a step of mapping [MAP] a set of image sample values [SV] from a departure space [DEP] to an arrival space [ARR] in accordance with a geometrical transformation [T], the method comprising the steps of

computing a zone in the departure space [ITL] by applying the inverse geometrical transformation [T.sup.-1] to a zone in the arrival space [TL] covering a group of image samples;

establishing a group of input values [IV] for the zone in the departure space [ITL], the group of input values [IV] comprising Boolean values [BV], a Boolean input value having a certain position (x_d, y_d) in the departure space [DEP] and designating the other values having the same position as being non-valid if the position is outside the set of image sample values;

constructing a Boolean shaped bitmap [BM] for the zone in the departure space [ITL], the boolean shaped bitmap [BM] comprised of a plurality of Boolean input values, each value having a certain coordinate position (x_d, y_d) in the departure space [DEP];

assigning a '1' value to those coordinate positions in the Boolean shaped bitmap [BM] in the departure space [ITL] corresponding to coordinate positions (x_d, y_d) of image samples [SV] located inside the zone in the departure space [ITL] and coordinate positions (x_d, y_d) of image samples [SV] not flagged as outside by shape information [SSV]

assigning a '0' value to those coordinate positions in the Boolean shaped bitmap [BM] in the departure space [ITL] corresponding to coordinate positions (x_d, y_d) of image samples located outside the zone in the departure space [ITL] or coordinate positions (x_d, y_d) of image samples flagged as being outside the zone in the departure space [ITL] by said shape information [SSV];

composing the group of image samples [SV~~TL~~] in the zone of the departure space [ITL] from the group of input values [IV], using the Boolean values [BV] to prevent those ~~preventing the~~ input values designated as being non-valid from contributing to an image sample [SV] by replacing the input values [IV] designated as being invalid with at least one other input value [IV] from inside the zone in the departure space [ITL] designated as being valid.

2. (Currently Amended) A device for composing an image [IM], ~~the composition comprising a step of~~ by mapping [MAP] a set of image sample values [SV] from a departure space [DEP] to an arrival space [ARR] in accordance with a geometrical transformation [T], the device ~~being arranged to perform the steps of~~comprising:

means for computing a zone in the departure space [ITL] by applying the inverse geometrical transformation [T.sup.-1] to a zone in the arrival space [TL] covering a group of image samples;

means for establishing a group of input values [IV] for the zone in the departure space [ITL], the group of input values [IV] comprising Boolean values [BV], a Boolean input value having a certain position (x_d, y_d) in the departure space [DEP] and designating the other values having the same position as being non-valid if the position is outside the set of image sample values;

means for constructing a Boolean shaped bitmap [BM] for the zone in the departure space [ITL], the boolean shaped bitmap [BM] comprised of a plurality of Boolean input values, each value having a certain coordinate position (xd, yd) in the departure space [DEP];

means for assigning a '1' value to those coordinate positions in the Boolean shaped bitmap [BM] in the departure space [ITL] corresponding to coordinate positions (x_d, y_d) of image samples [SV] located inside the zone in the departure space [ITL] and coordinate positions (x_d, y_d) of image samples [SV] not flagged as outside by shape information [SSV]

means for assigning a '0' value to those coordinate positions in the Boolean shaped bitmap [BM] in the departure space [ITL] corresponding to coordinate positions (x_d, y_d) of image samples located outside the zone in the departure space [ITL] or coordinate positions (x_d, y_d) of image samples flagged as being outside the zone in the departure space [ITL] by said shape information [SSV];

means for composing the group of image samples [SV~~TL~~] in the zone of the

departure space [ITL] from the group of input values [IV], using the Boolean values [BV]

to prevent those ~~preventing the~~ input values designated as being non-valid from

contributing to an image sample [SV] by replacing the input values [IV] designated as

being invalid with at least one other input value [IV] from inside the zone in the departure

space [ITL] designated as being valid.

3. (Currently Amended) A computer program product for an image composition device,

the computer program product comprising a set of instructions which, when loaded into

the image composition device, cause the device to map [MAP] a set of image sample

values [SV] from a departure space [DEP] to an arrival space [ARR] in accordance with a

geometrical transformation [T] by performing the steps of:

computing a zone in the departure space [ITL] by applying the inverse geometrical

transformation [T.sup.-1] to a zone in the arrival space [TL] covering a group of image

samples;

establishing a group of input values [IV] for the zone in the departure space [ITL],

the group of input values [IV] comprising Boolean values [BV], a Boolean input value

having a certain position (x_d, y_d) in the departure space [DEP] and designating the other

values having the same position as being non-valid if the position is outside the set of

image sample values;

constructing a Boolean shaped bitmap [BM] for the zone in the departure space

[ITL], the boolean shaped bitmap [BM] comprised of a plurality of Boolean input values,

each value having a certain coordinate position (xd, yd) in the departure space [DEP];

assigning a '1' value to those coordinate positions in the Boolean shaped bitmap

[BM] in the departure space [ITL] corresponding to coordinate positions (x_d, y_d) of image

samples [SV] located inside the zone in the departure space [ITL] and coordinate

positions (x_d, y_d) of image samples [SV] not flagged as outside by shape information

[SSV]

assigning a '0' value to those coordinate positions in the Boolean shaped bitmap

[BM] in the departure space [ITL] corresponding to coordinate positions (x_d, y_d) of image

samples located outside the zone in the departure space [ITL] or coordinate positions $(x_d,$

$y_d)$ of image samples flagged as being outside the zone in the departure space [ITL] by

said shape information [SSV];

composing the group of image samples [SV~~IL~~] in the zone of the departure space

[ITL] from the group of input values [IV], using the Boolean values [BV] to prevent

those ~~preventing the~~ input values designated as being non-valid from contributing to an

image sample [SV] by replacing the input values [IV] designated as being invalid with at

least one other input value [IV] from inside the zone in the departure space [ITL]

designated as being valid.